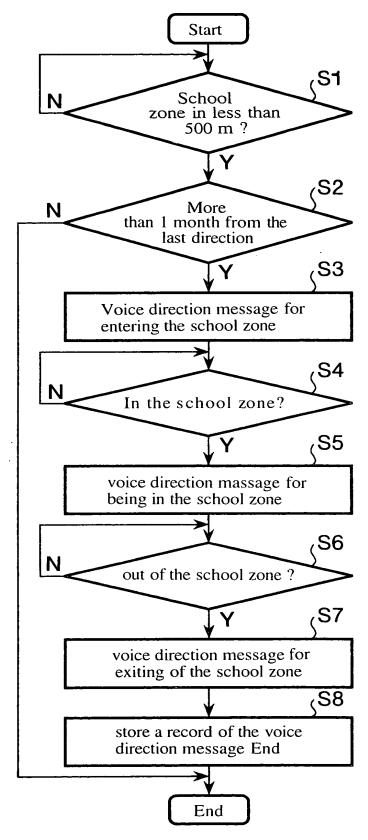


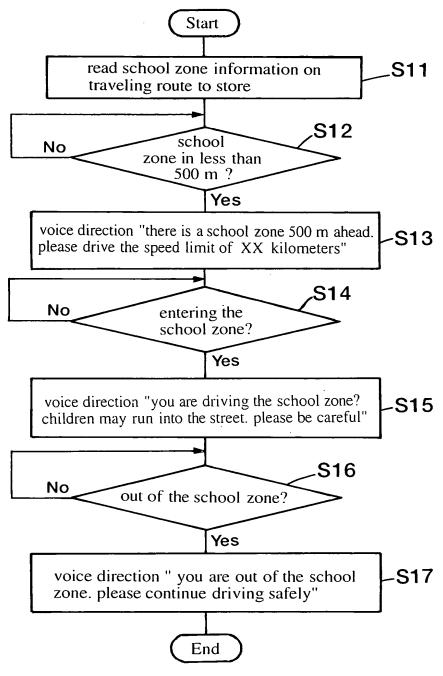
Fig.2



## Fig.3

Setting for the voice direction shout facilities	
output every time output sometimes	
output regularly	
once in (how many) times once in (how many) weeks	
output irregularly	

Fig.4



## Fig.5

School zone					
No.	School name	address	school days	time zone	Speed Limit
Ţ.	OOelmentary	~state~county	Jannary 8,9,10	Jannary 8,9,10 Mon~SatAM8:00~9:00	1/ -/100
-	school	OOcity	February 1, 2, 3	Mon~SatPM2:00~4:00	ZUKM/N
C	△△middle	~state~county	Jannary 8,9,10	Jannary 8,9,10 Mon~SatAM7:30~8:30	
7	school	△△city	February 1,2,3	Mon~SatPM3:30~5:30	SUKM/n
ď	XXelmentary	~state~county	Jannary 8,9,10	Jannary 8,9,10 Mon~SatAM8:00~9:00	1 1 4 /h
)	school	XXcity	February 1, 2, 3	Mon~SatPM2:00~4:00	

Fig.6 Start read school zone information on **S21** traveling route to store **S22** No school zone in less than 500 m? Yes voice direction "there is a school zone 500 m ahead, please drive the speed limit of XX **S23** kilometers" **S24** Yes vehicle speed  $\leq XX$  km No output deceleration command signal **S25** and give voice direction thereof S26 No entering the school zone? Yes voice direction "you are driving the school zone? children may run into the street. **S27** please be careful" **S28** No out of the school zone? Yes **S29** voice direction "you are out of the school zone. continue driving safely" End

liquid crystal ĸ remote control **DVD-ROM** driver disply 3 communication • ROM • RAM • VRAM storage portion interface ,22  $\sim$  20 23 721 76 image processor continuous driving detection means driver change detection means monotory driving detection means CPU .12 device main body  $\sim$ 15|voice recognition voice processor processor sensor signal portion  $\frac{1}{2}$ direction sensor various sensors vehicle speed microphone speaker sensor Fig.7 37 19~ 2

communication

externlal

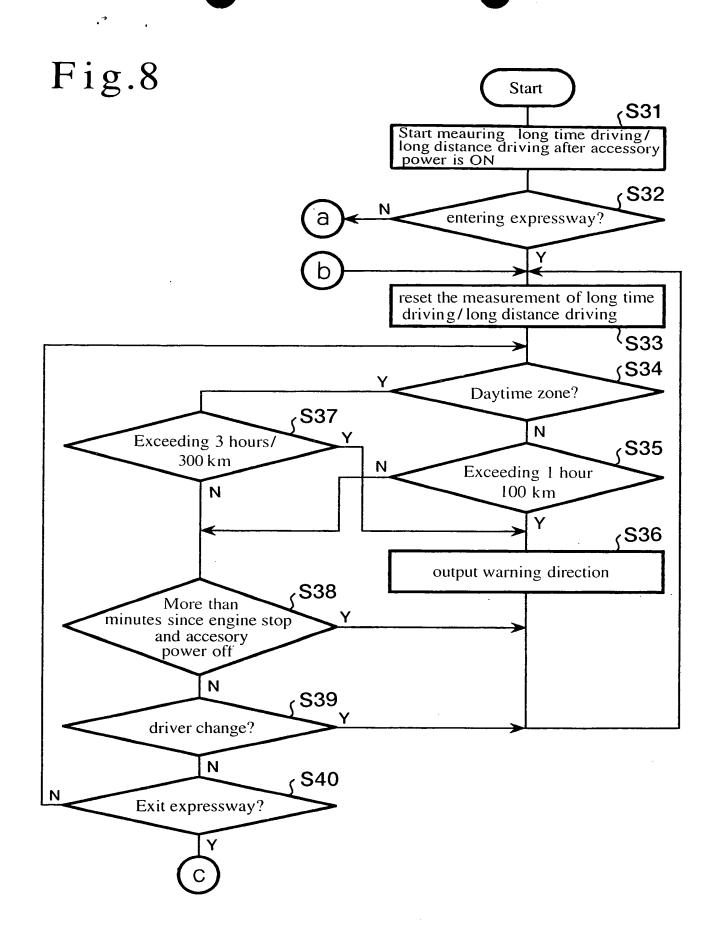
controller

receiver GPS

0

**6**8

 $\infty$ 



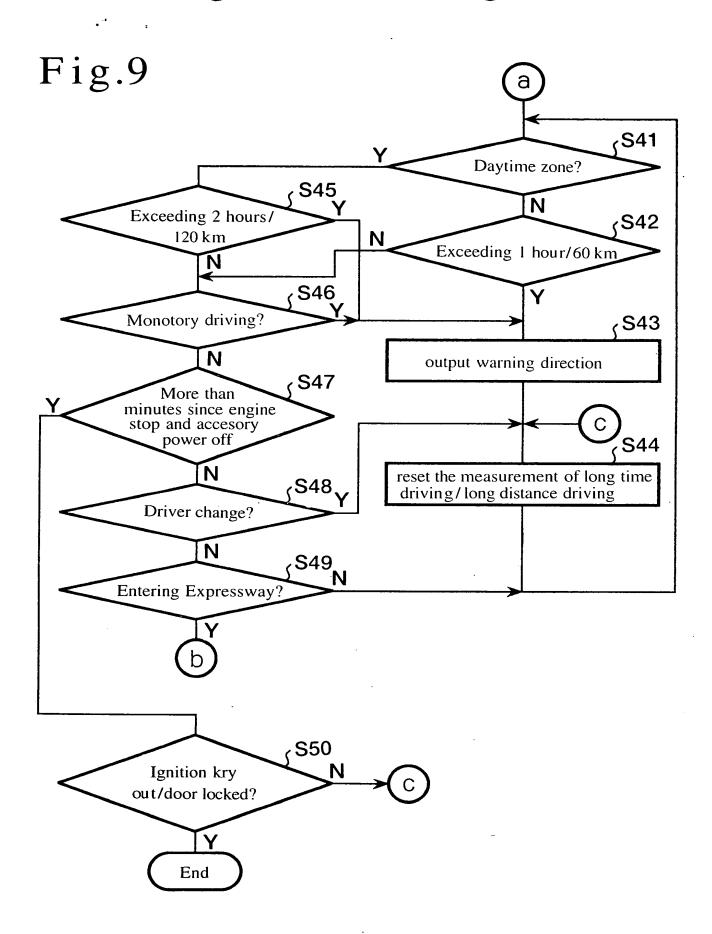


Fig. 10

Fi

 $\sim$ 

→ time (h)

ta ta

421

ᆍ

Fig.11

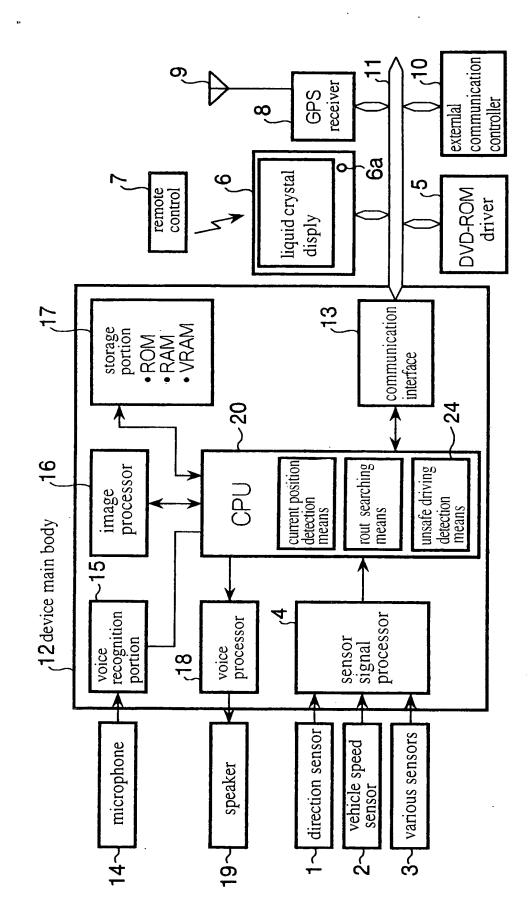


Fig.12(a)

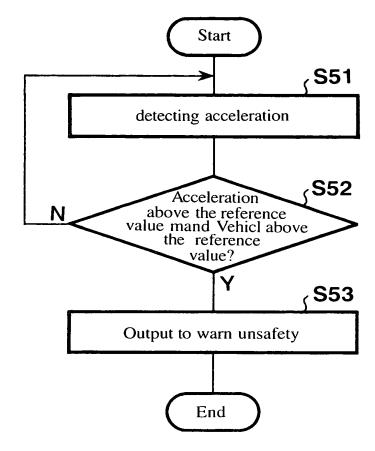


Fig.12(b)

Acceleration ±G	Vehicle speed V
G≧G1	V≧V 1
G≧G2>G1	V≧V2>V1
•	•
G≧Gn>Gn-1	V≧Vn>Vn-1

Fig. 13(a)

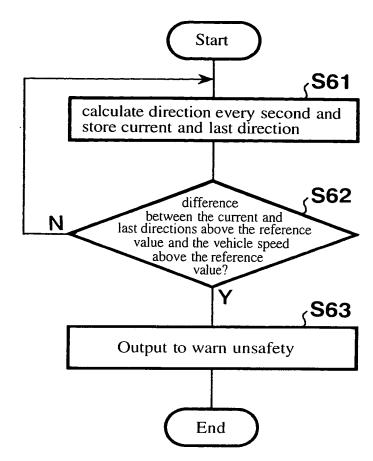


Fig.13(b)

Direction difference Θ	Vehicle speed V
θ≧θ1	V≧V1
$\theta \ge \theta$ 2 < $\theta$ 1	V≧V2>V1
•	•
$\theta \ge \theta n < \theta n - 1$	V≧Vn>Vn-1

Fig.14

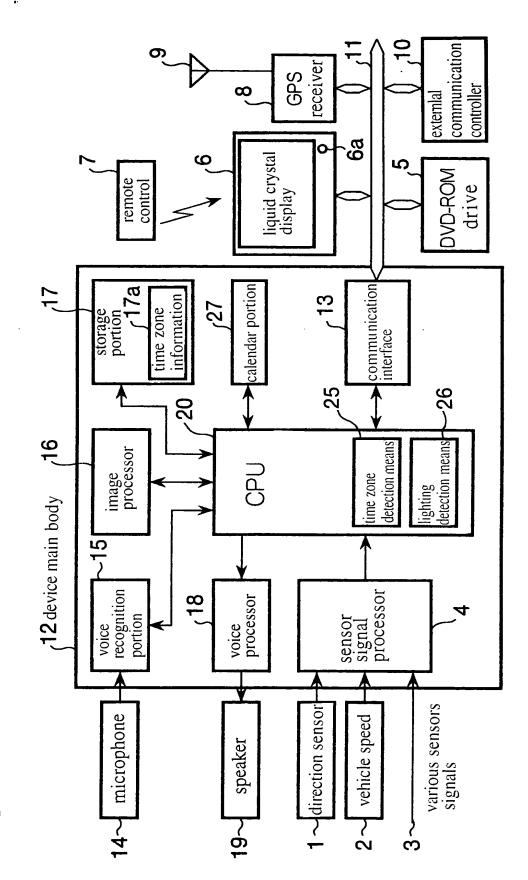


Fig. 15

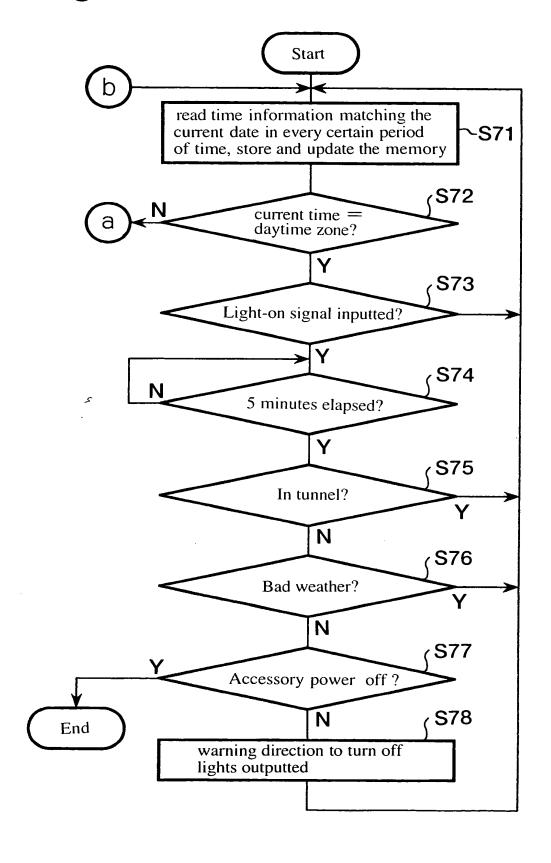


Fig.16

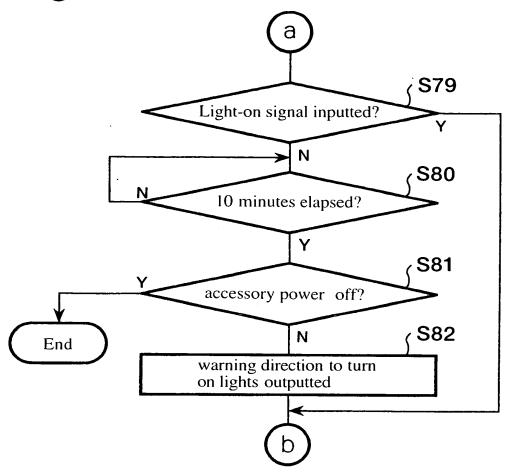


Fig.17

17a	
Longitude Lo	139 <lo≦140< th=""></lo≦140<>
Latitude La	34 <la≦36< th=""></la≦36<>
Date	Dec.15~Jan.5
Time zone	AM6:50~PM4:30